

### **Amendments to the Specification**

**Please replace the paragraph beginning at page 12, line 7, with the following rewritten paragraph:**

In still another aspect of the present invention, there is provided a method for controlling a wiper device, driving a wiper arm to reciprocate between an upper reversal position and a lower reversal position for a wiping operation, wherein a reference position, a stored position for holding the wiper arm at rest when the wiper device is stopped and a lower limit position for mechanically restricting the operation of the wiper arm are arranged respectively between the upper reversal position and the lower reversal position, below the lower reversal position and below the stored position and, when the wiper arm is driven to reciprocate between the lower reversal position and the stored position and if the wiper arm is driven toward the side of the reference position beyond the lower limit reversal position, it is moved to the lower limit position.

**Please replace the paragraph beginning at page 12, line 21, with the following rewritten paragraph:**

Thus, according to the invention, when the wiper arm is driven to reciprocate between the lower reversal position and the stored position and if the wiper arm is driven toward the side of the reference position beyond the lower limit reversal position, it is moved to the lower limit position. In other words, if the wiper arm that is supposed to reciprocate between the lower reversal position and the stored position is driven to go beyond the lower reversal position, it is highly possible that the wiper arm position is not accurately grasped. Therefore, if such is the case, the wiper arm is driven to move to the lower limit position once in the subsequent operation. Since it is possible to accurately grasp the wiper arm position at the lower limit position as described above, the wiper arm position can be grasped accurately and the positional displacement can be dissolved by the above control method.

**Please replace the paragraph beginning at page 15, line 26, with the following rewritten paragraph:**

In still another aspect of the present invention, there is provided a method for controlling a wiper device, driving a wiper arm by means of a motor to reciprocate between an upper reversal position and a lower reversal position for a wiping operation and controlling the operation of the wiper device by detecting the wiper arm position by means of the count value of the pulse signal output as a result of the rotary motion of the motor, wherein a reference position for resetting the count value of the pulse signal to a reference value, a stored position for holding the wiper arm at rest when the wiper arm is stopped and a lower limit position for mechanically restricting the operation of the wiper arm and causing the count value of the pulse signal to show a predetermined value are arranged respectively between the upper reversal position and the lower reversal position, below the lower reversal position and below the stored position and, when the wiper arm is driven to reciprocate between the lower reversal position and the stored position and if the count value of the pulse signal shows a value indicating as if the wiper arm were positioned at the side of the reference position beyond the lower limit reversal position, the wiper arm is moved to the lower limit position and the count value of the pulse signal is reset to the predetermined value in response to the arrival of the wiper arm to the lower limit position.

**Please replace the paragraph beginning at page 16, line 21, with the following rewritten paragraph:**

Thus, according to the invention, when the wiper arm is driven to reciprocate between the lower reversal position and the stored position and if the count value of the pulse signal shows a value indicating as if the wiper arm were positioned at the side of the reference position beyond the lower limit reversal position, the wiper arm is moved to the lower limit position. If the pulse count value exceeds the value for the lower reversal position, although the wiper arm is supposed to be driven to reciprocate between the lower reversal position and the stored position, it is highly possible that the wiper arm position is not accurately grasped. Therefore, if such is the case, the

wiper arm is driven to move to the lower limit position once in the subsequent operation. Since it is grasped that the count value of the pulse signal that indicates the position of the wiper arm shows a predetermined value at the lower limit position, the wiper arm position can be grasped accurately and the positional displacement can be dissolved by means of the above control method.